

**IN THE CLAIMS:**

Please amend claims 1-8 to read as follows:

- ✓* 1. (Amended) A position control method for feed drive equipment in which a plurality of feed drive mechanisms disposed in parallel for feeding a movable body are individually driven by servo motors, the position control method comprising:  
determining torque of the servo motors, and  
correcting position commands of at least one servo motor in dependence on the determined torque so that the servo motors have matching torque.
- ✓* 2. (Amended) A position control method for feed drive equipment according to claim 1, wherein torque of the servo motors are matched to an average of the determined torque.
- ✓* 3. (Amended) A position control method for feed drive equipment according to claim 1, wherein torque of one servo motor is matched to the determined torque of another servo motor.
- ✓* 4. (Amended) A position control method for feed drive equipment according to claim 1, wherein a value of a torque command to be input to a current controller of each servo motor is determined as the torque of the servo motor.

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- Marked Out*
- AC*
5. (Amended) A position control system for feed drive equipment in which a plurality of feed drive mechanisms disposed in parallel for feeding a movable body are individually driven by servo motors, the position control system comprising:  
a controller for determining torque of the servo motors, and correcting position commands of at least one servo motor in dependence on the determined torque so that the servo motors have matching torque.
6. (Amended) A position control system for feed drive equipment according to claim 5, wherein the controller makes torque of the servo motors match to an average of the determined torque.
7. (Amended) A position control system for feed drive equipment according to claim 5, wherein the controller makes torque of one servo motor match to the determined torque of another servo motor.
8. (Amended) A position control system for feed drive equipment according to claim 5, wherein the controller determines a value of a torque command to be input to a current controller of each servo motor, as the torque of the servo motor.

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